

FIG. 1

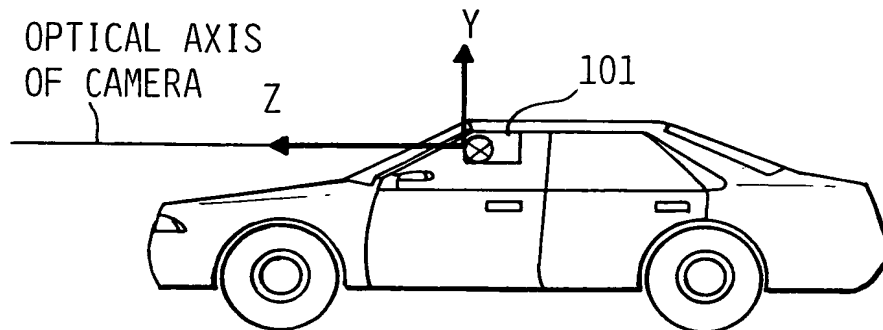


FIG 2A

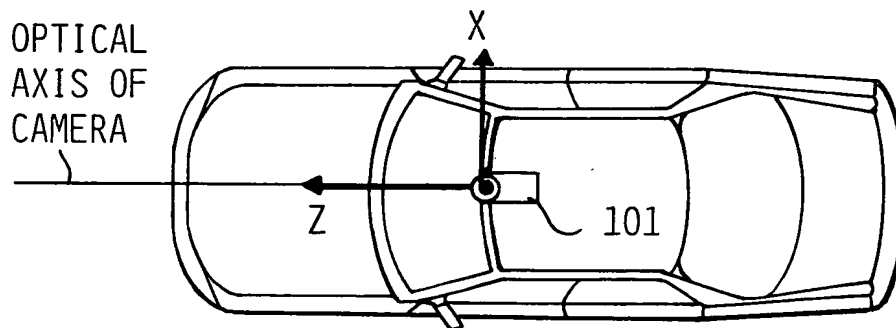


FIG 2B

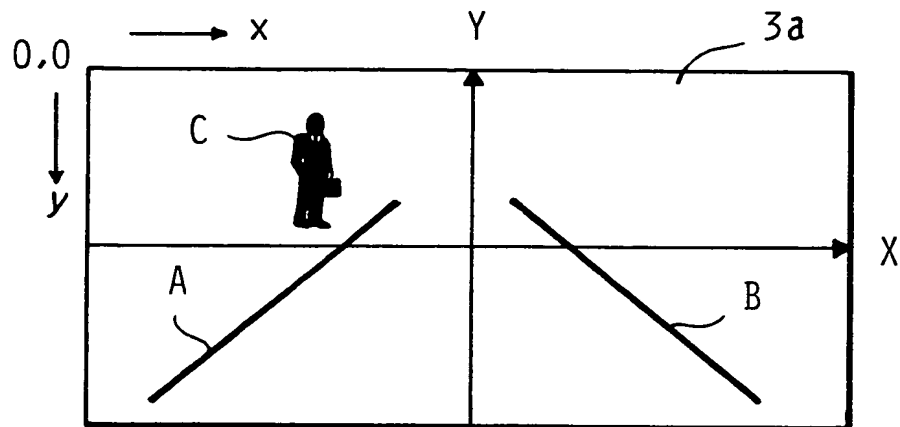


FIG. 3

CONVERSION TO  
BINARY VALUE

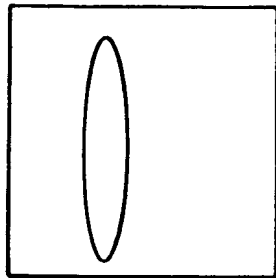


FIG. 4A

FINER LINE  
FORMATION

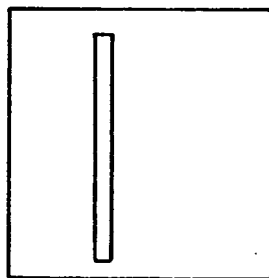


FIG. 4B

EXPANSION

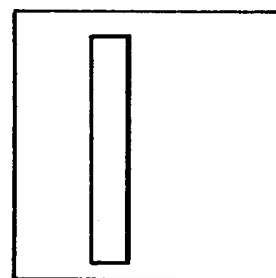


FIG. 4C

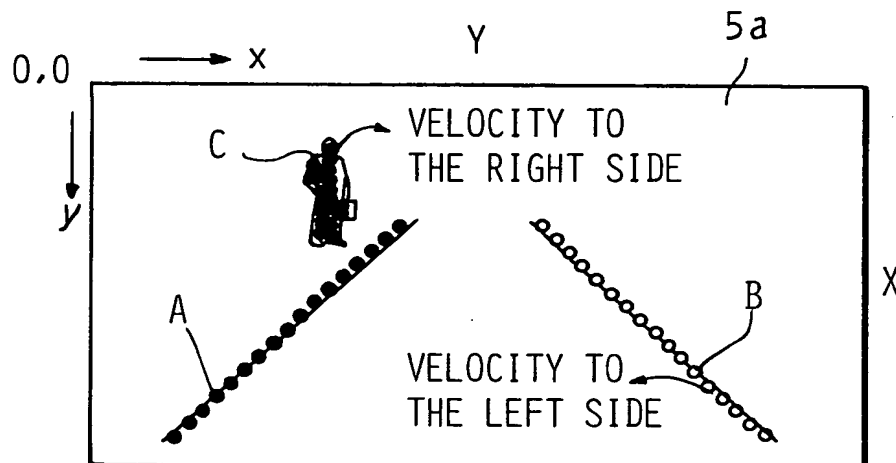


FIG. 5

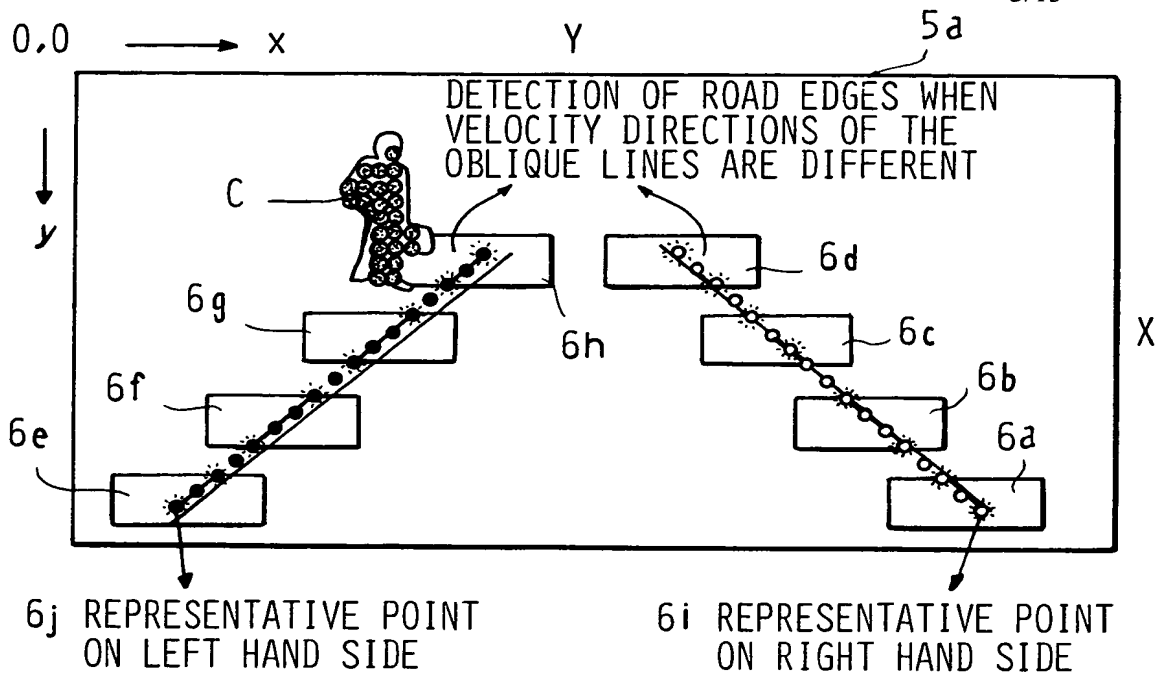


FIG. 6

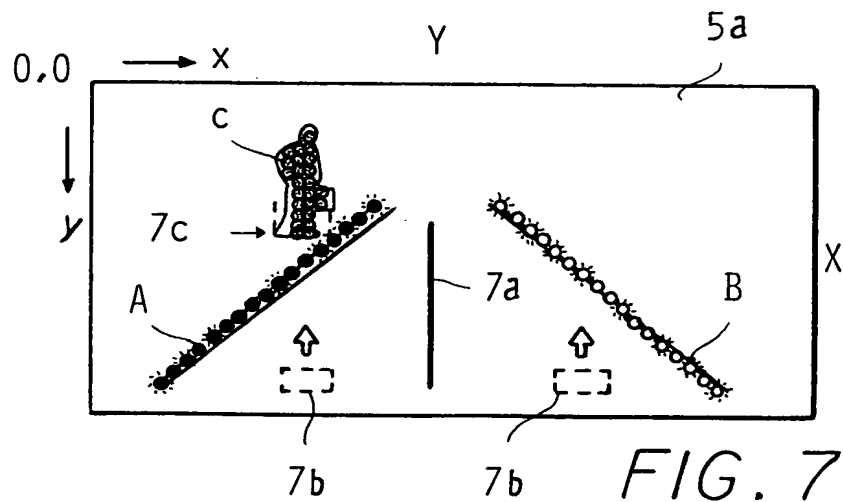


FIG. 7

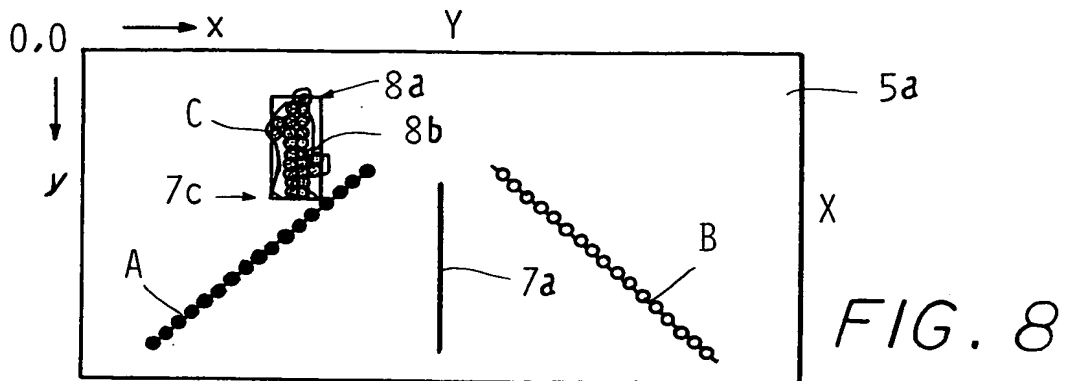


FIG. 8

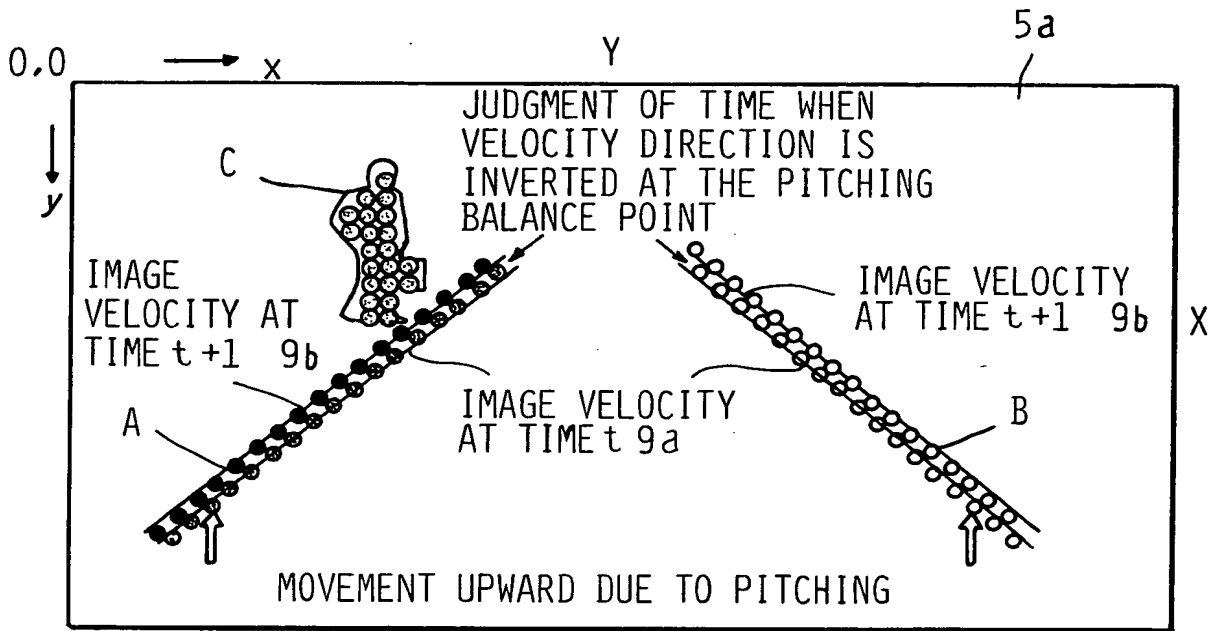


FIG. 9

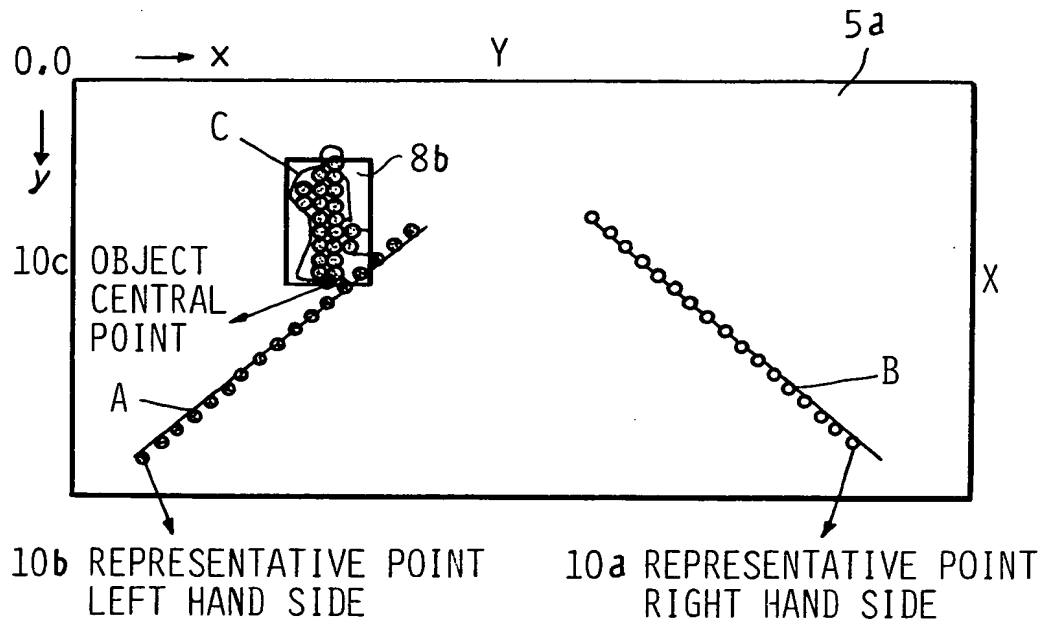


FIG. 10

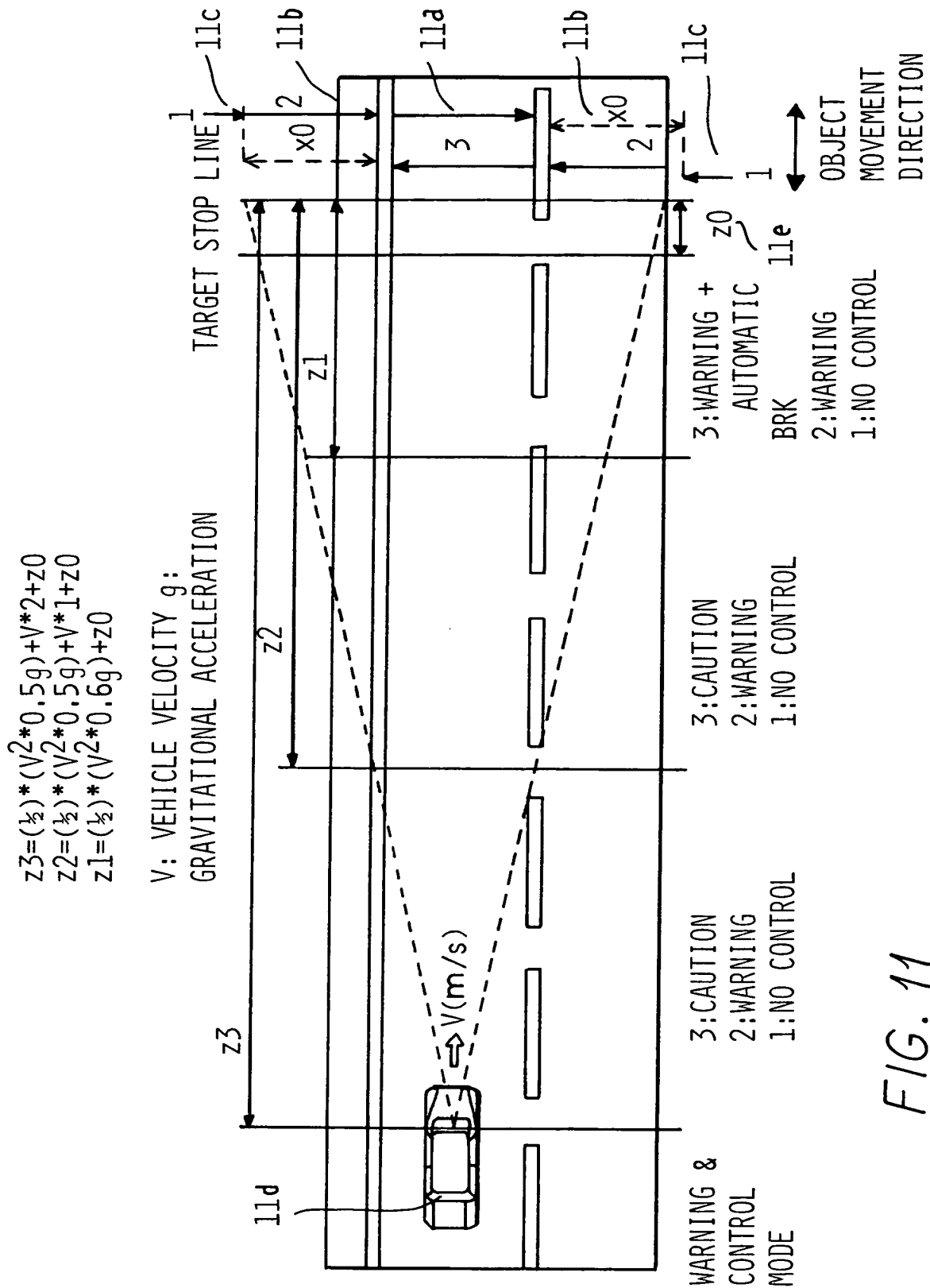


FIG. 11

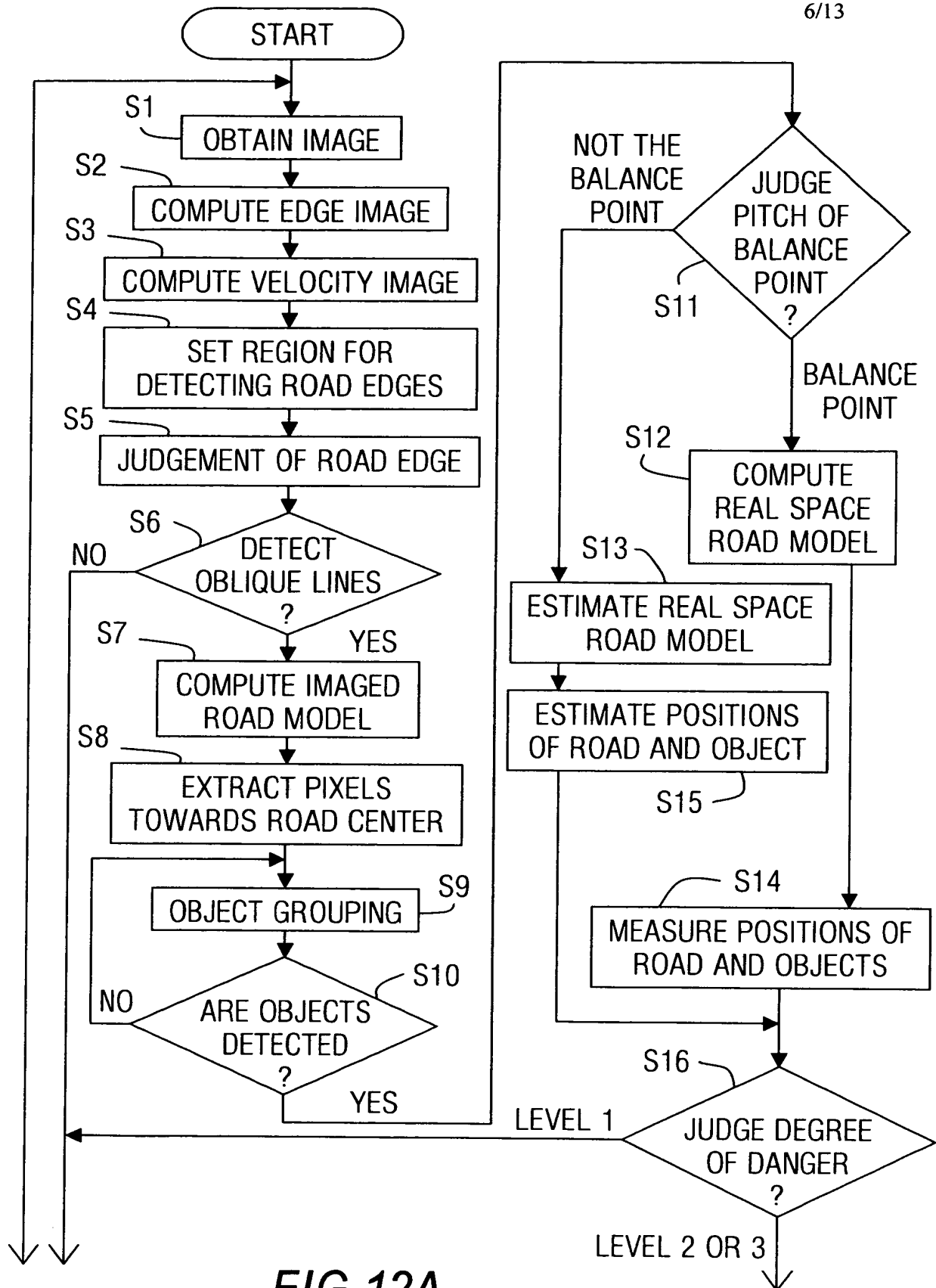
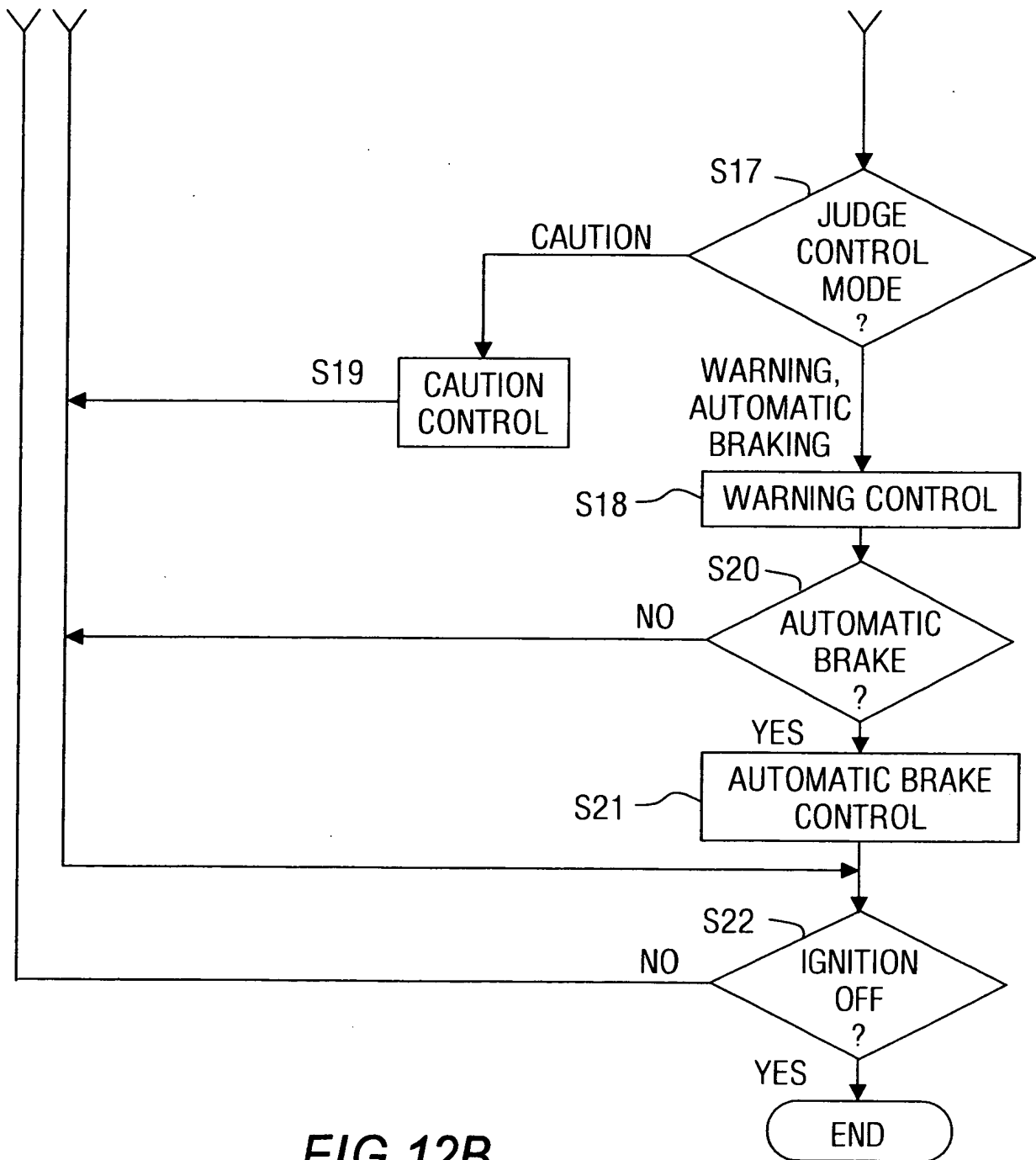


FIG 12A



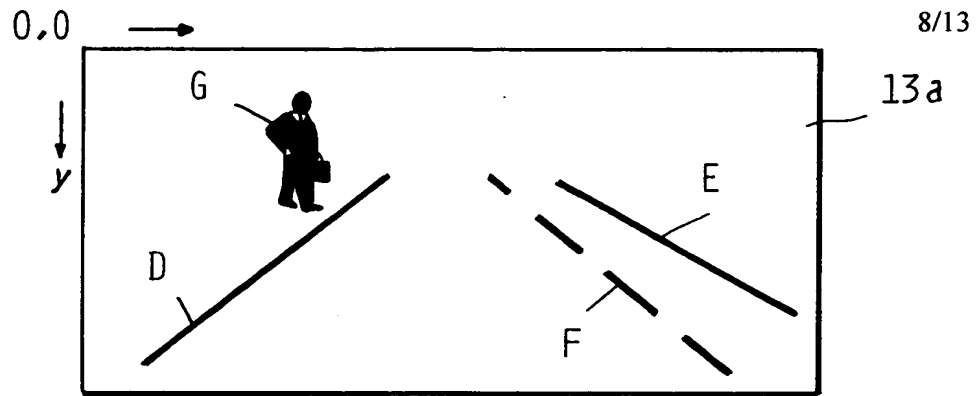


FIG. 13

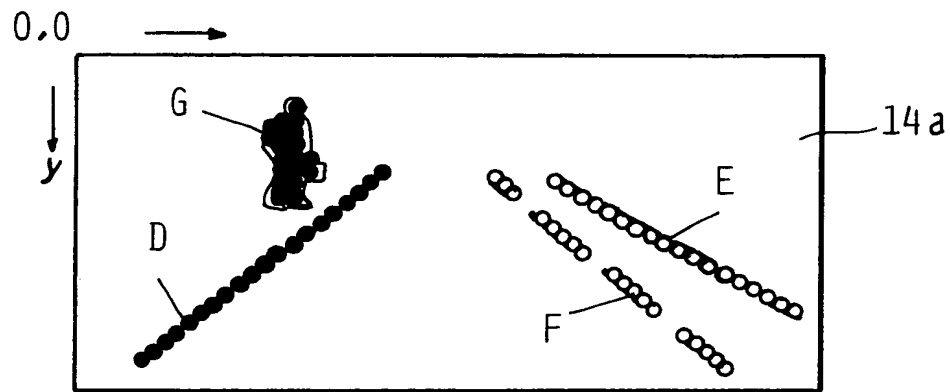


FIG. 14

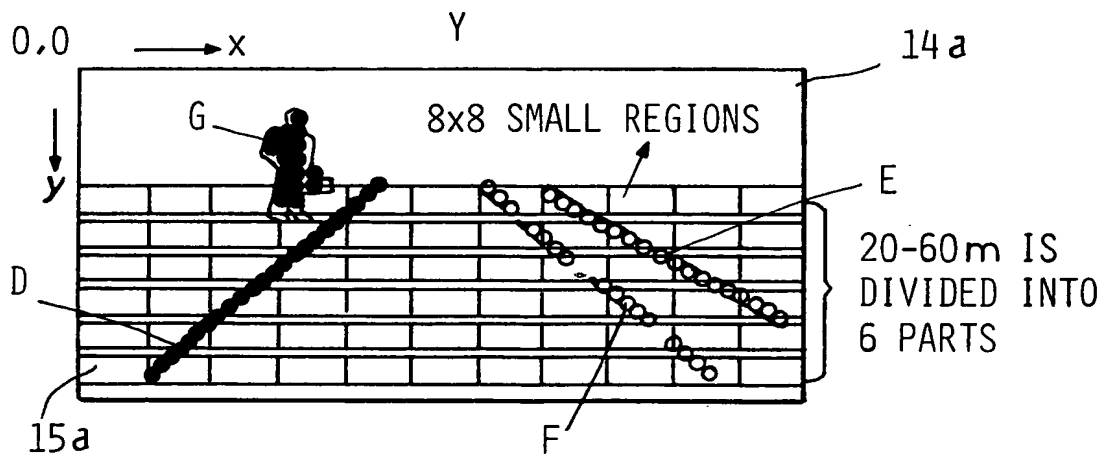


FIG. 15

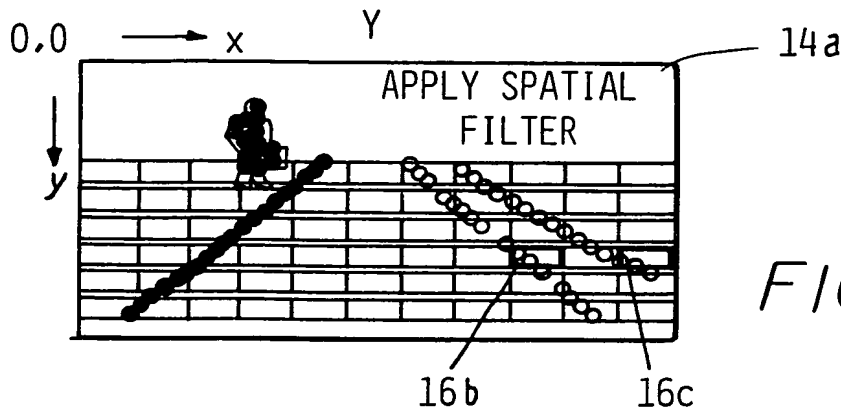


FIG. 16A

16a

1	1	0	0	0
0	0	1	0	0
0	0	0	1	1

IDENTIFIED AS A DOT CANDIDATE WHEN VELOCITY IS DETECTED  
 ABOVE AND/OR BELOW THE DOT, IN THE OBLIQUE DIRECTION

IF A LINE SECTION FORMED BY THREE OR MORE DOT  
 CANDIDATES SATISFIES THE SLOPE CONDITION, IT  
 IS DETECTED AS AN OBLIQUE LINE CANDIDATE

FIG. 16B

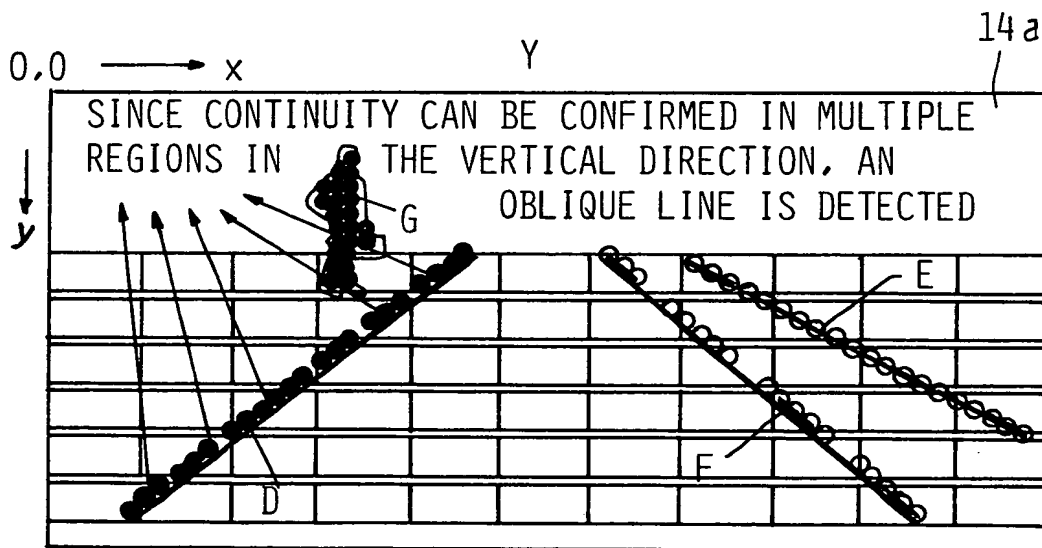


FIG. 17

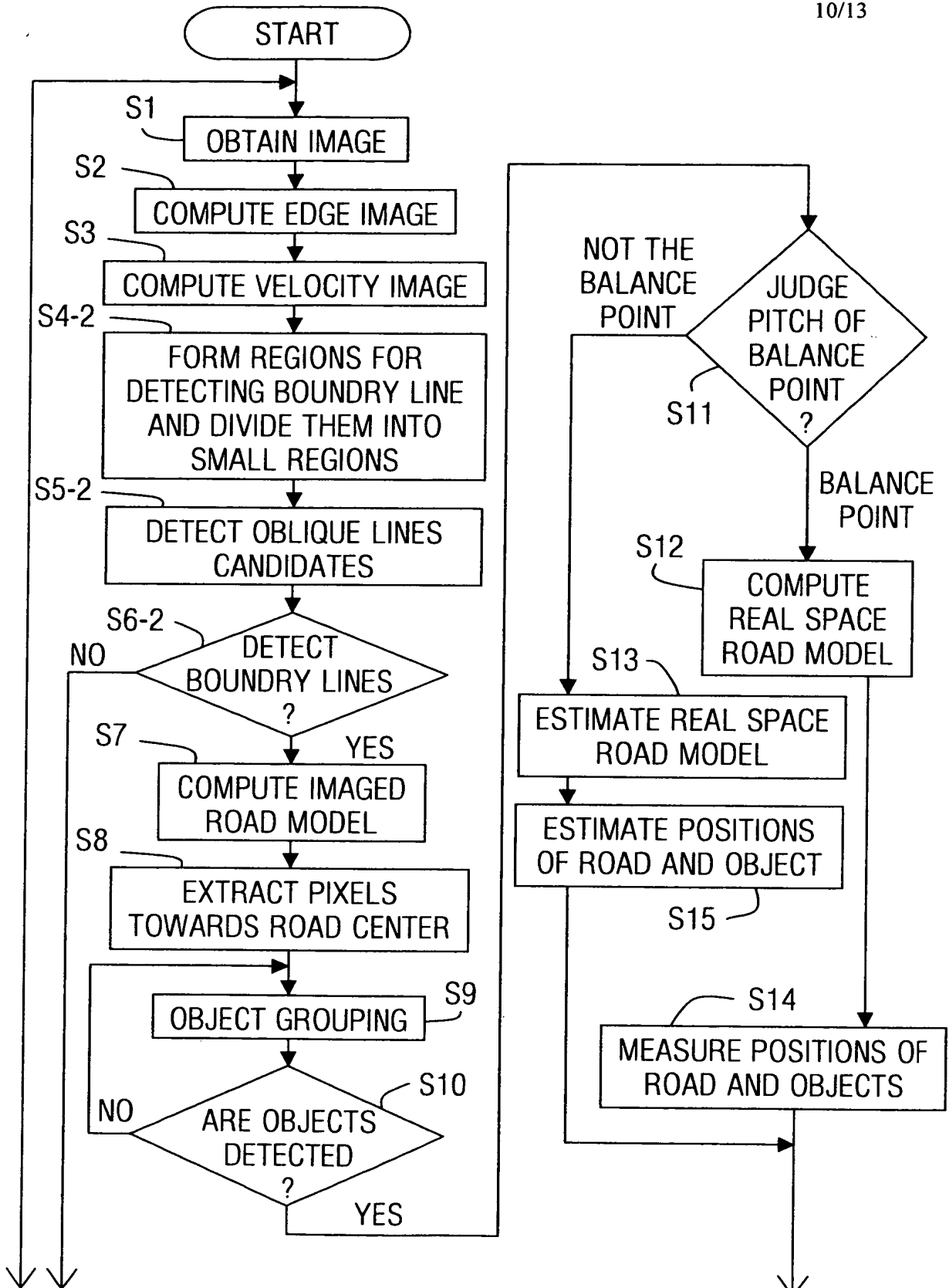


FIG 18A

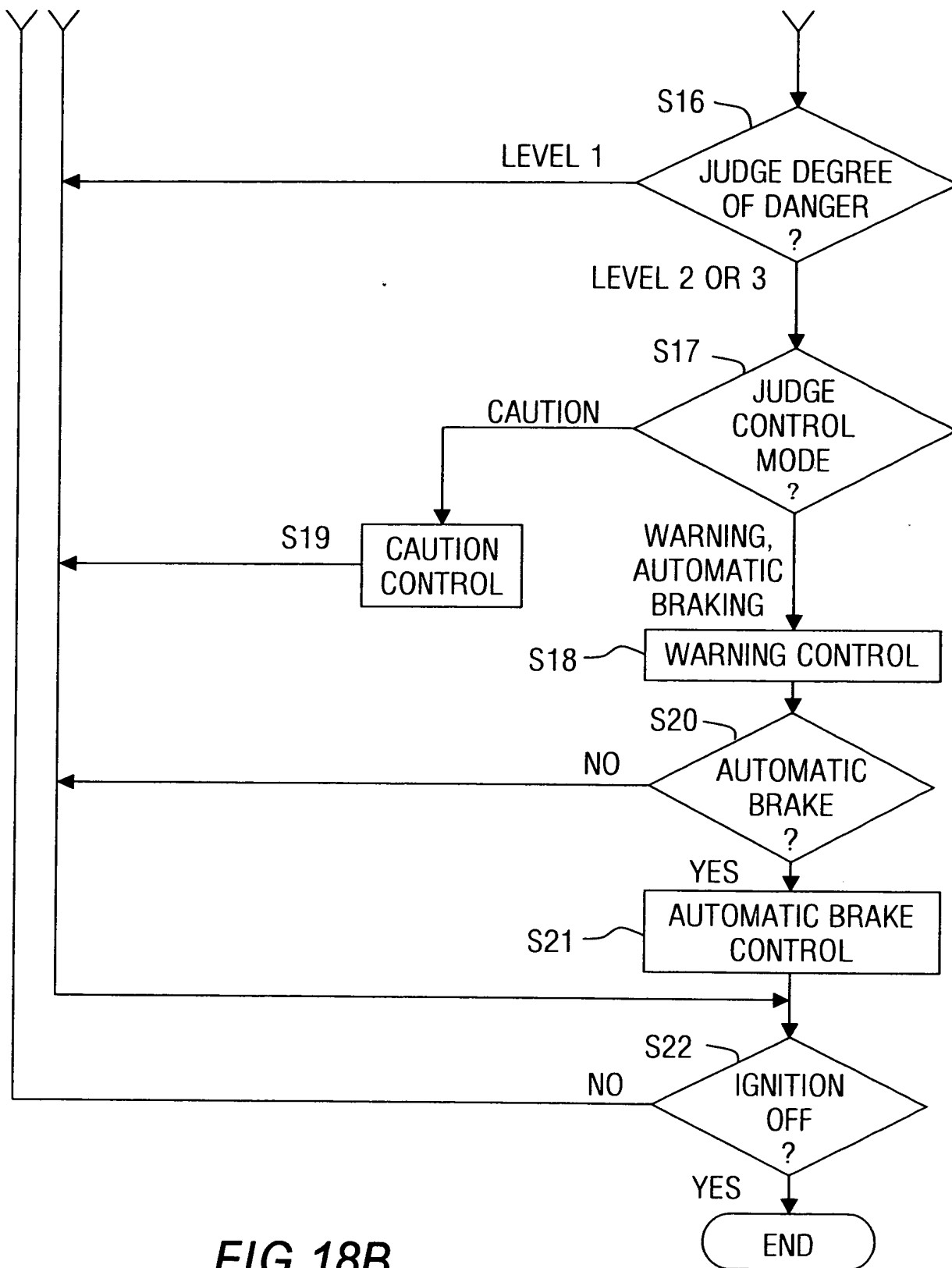


FIG 18B

FIG. 19

